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Parodi

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(54) **VOLTAGE-CURRENT PHASE-BASED METHOD FOR LINEAR AND ROTARY TRANSFORMER SYSTEMS, AND ASSOCIATED SYSTEMS AND METHODS**

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H01F 21/00 (2006.01)
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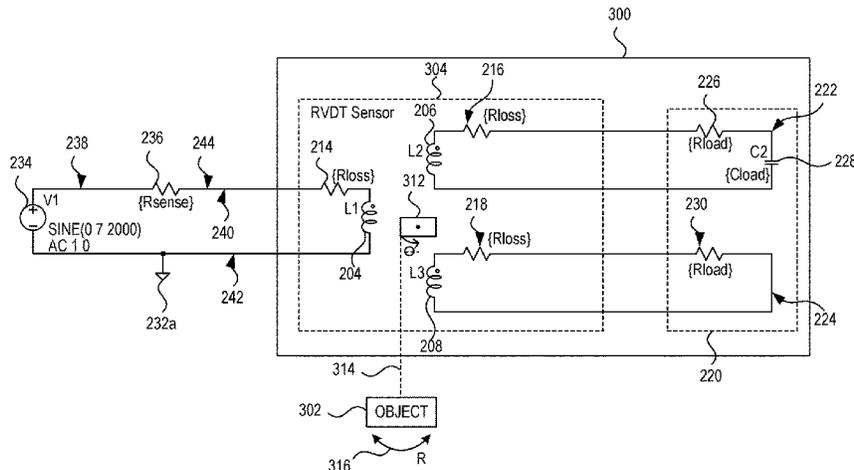
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CPC **G01D 5/2046** (2013.01); **H01F 21/065** (2013.01); **H01F 27/28** (2013.01)

(58) **Field of Classification Search**
CPC G01D 3/028; G01D 5/20; G01D 5/22; G01D 5/2216; G01D 5/2291;
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(57) **ABSTRACT**

A representative phase-shift based method for using a transformer system to detect movement of an object, and associated systems and methods are disclosed. A representative transformer system detects movement of an object and includes an excitation coil configured to receive an excitation coil input signal that results from an input sinusoidal signal. The transformer further includes first and second sensing coils, and a core configured to be operatively coupled to the object. The core moves relative to the first and second sensing coils when the object moves. First and second impedance loads are connected to the first and second sensing coils, respectively. The two impedance loads have different phase-shifting characteristics. A phase-shift sensing circuit determines a phase-shift between the excitation coil input signal and the input sinusoidal signal that is correlated with a position of the core relative to the first and second sensing coils.

20 Claims, 14 Drawing Sheets



Related U.S. Application Data

continuation of application No. 16/899,458, filed on Jun. 11, 2020, now Pat. No. 11,467,003.

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(51) **Int. Cl.**

H01F 21/06 (2006.01)
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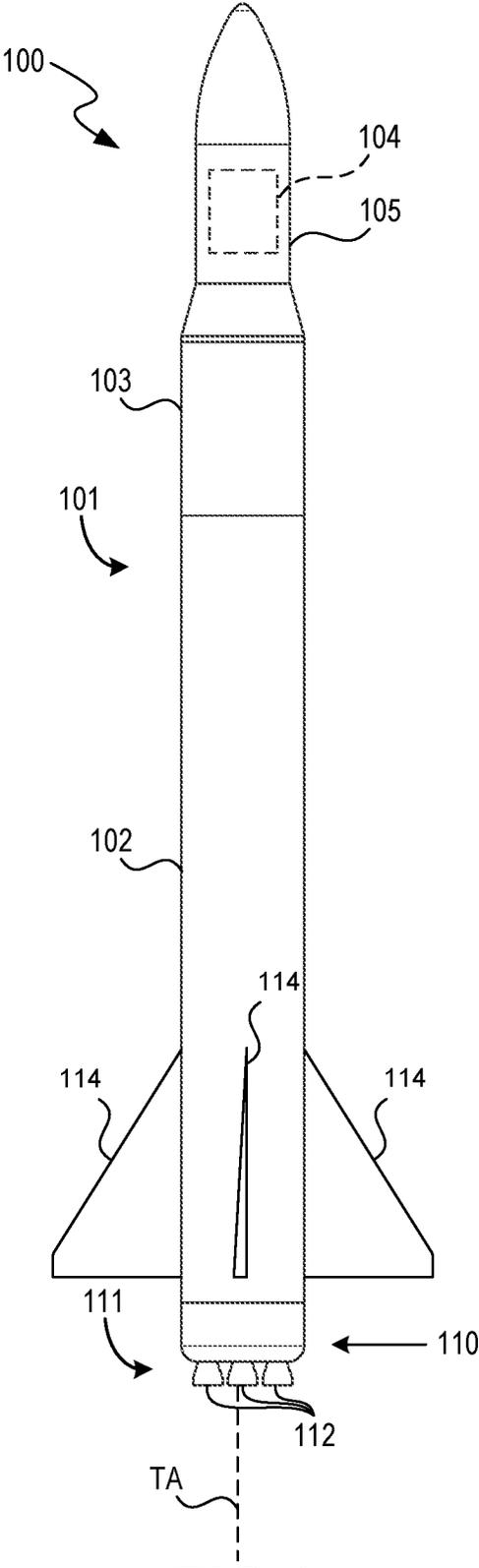


FIG. 1

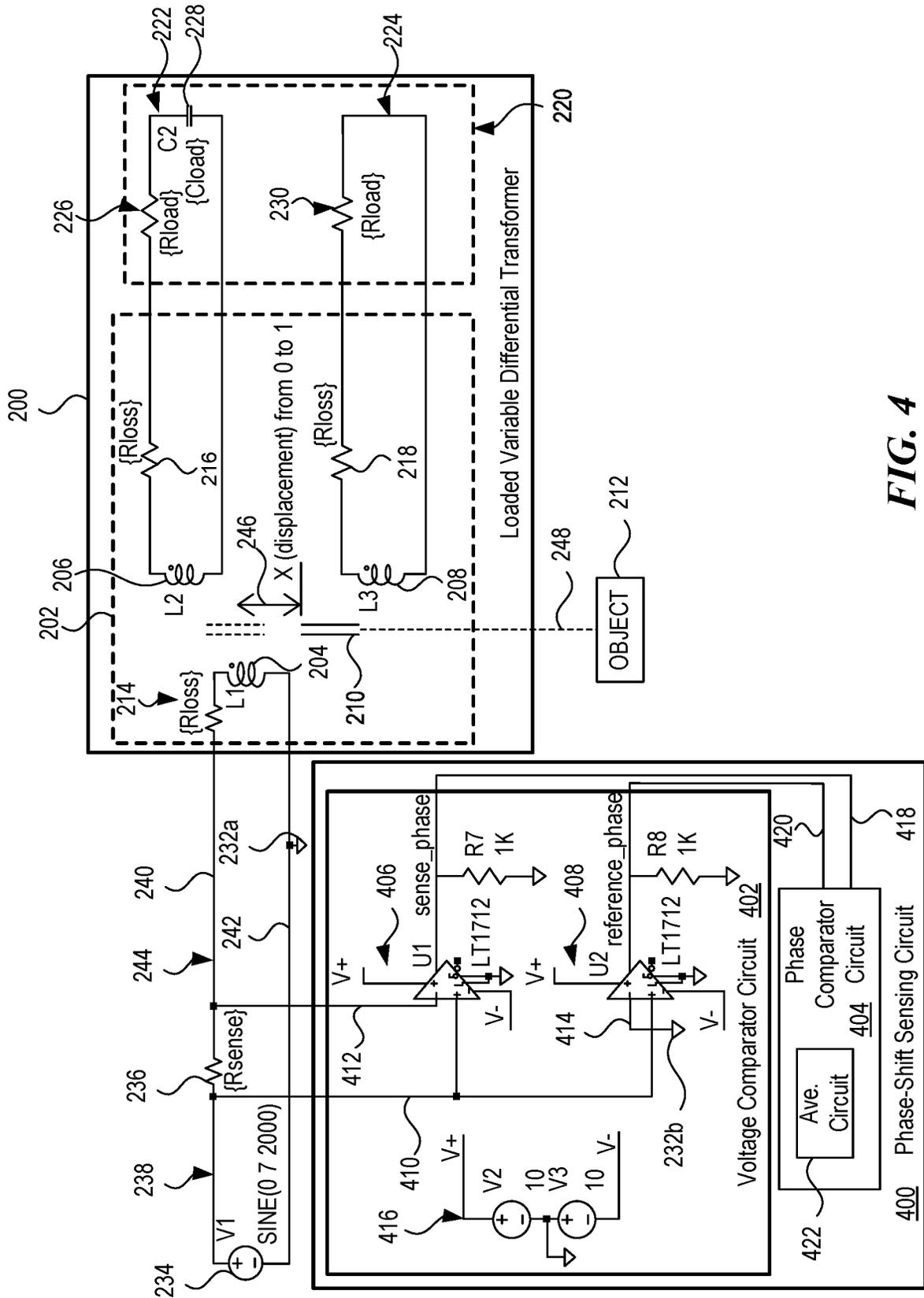


FIG. 4

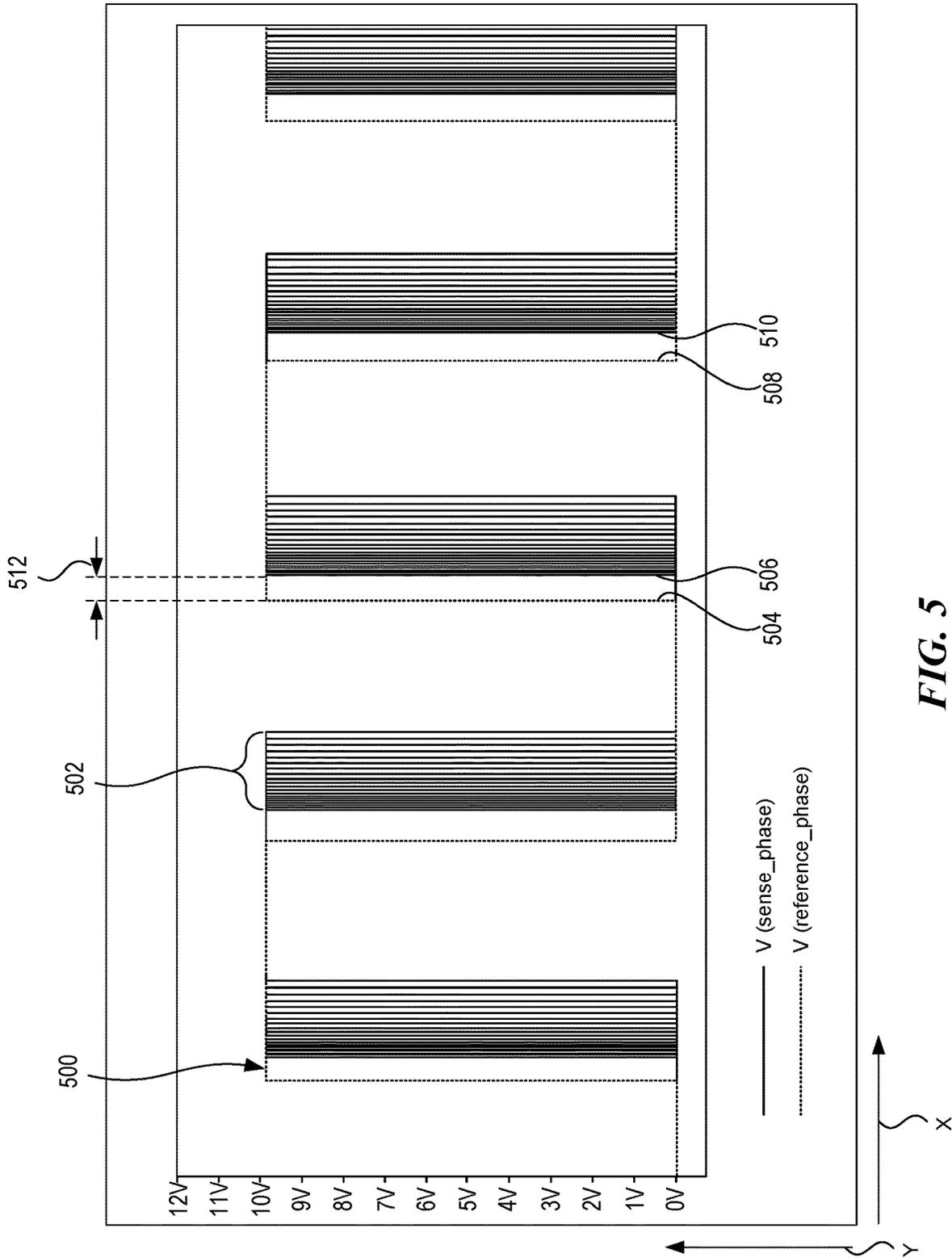


FIG. 5

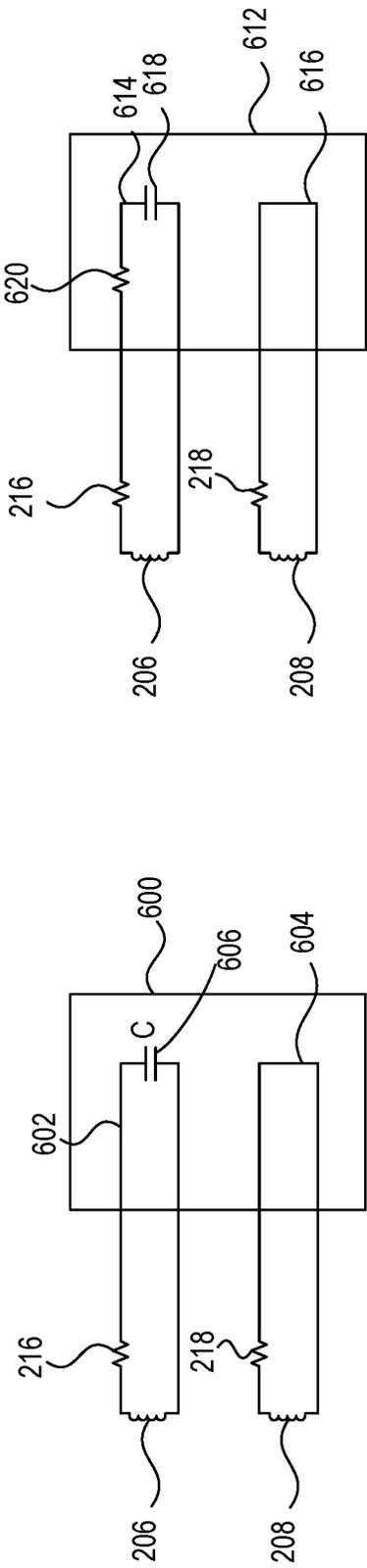


FIG. 6A

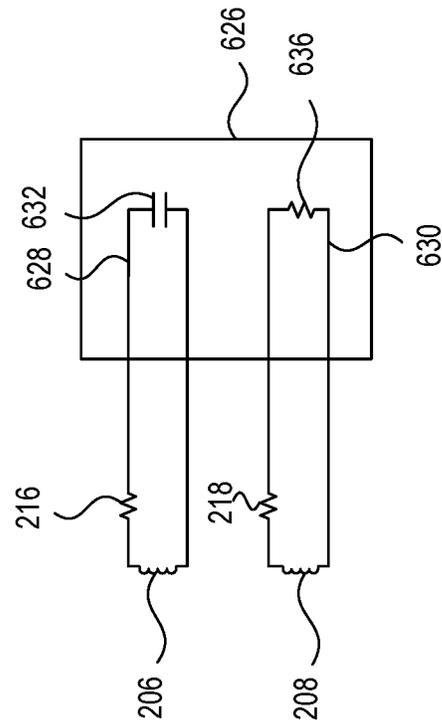


FIG. 6C

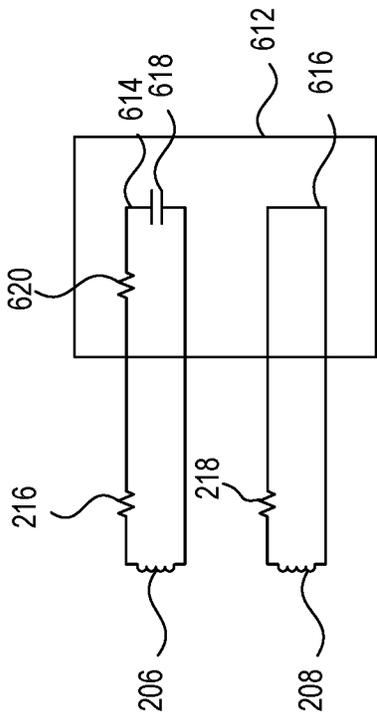


FIG. 6B

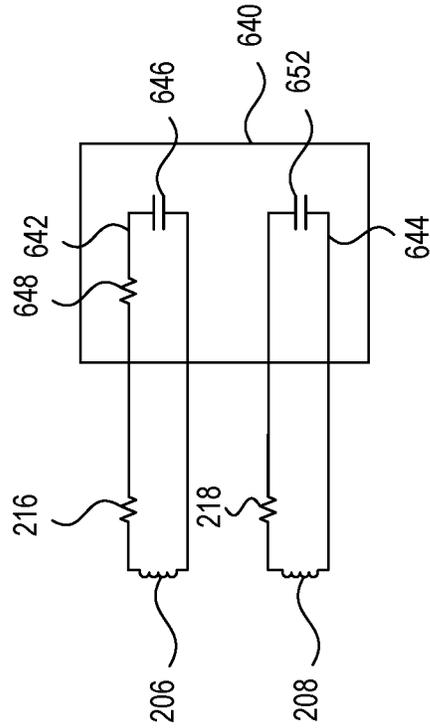


FIG. 6D

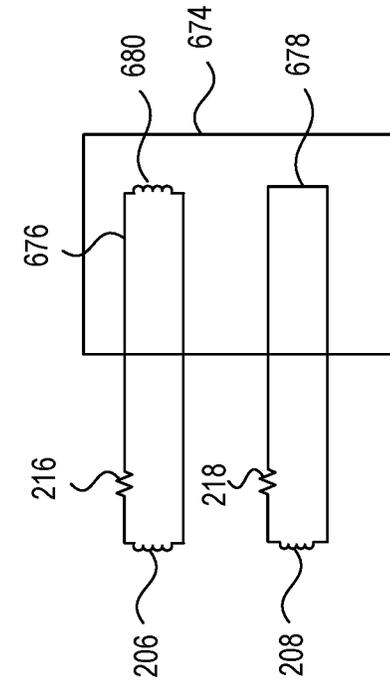


FIG. 6E

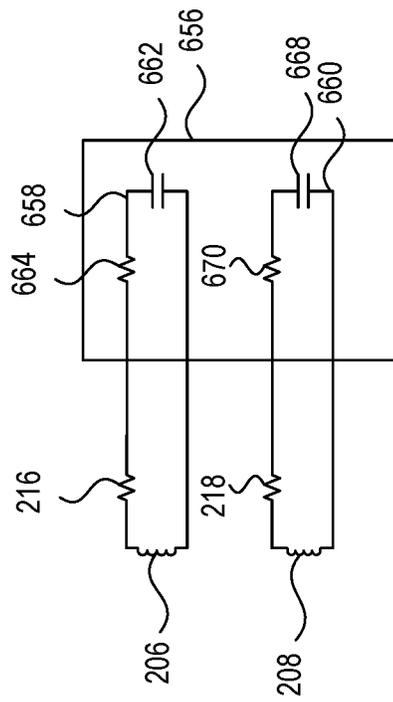


FIG. 6F

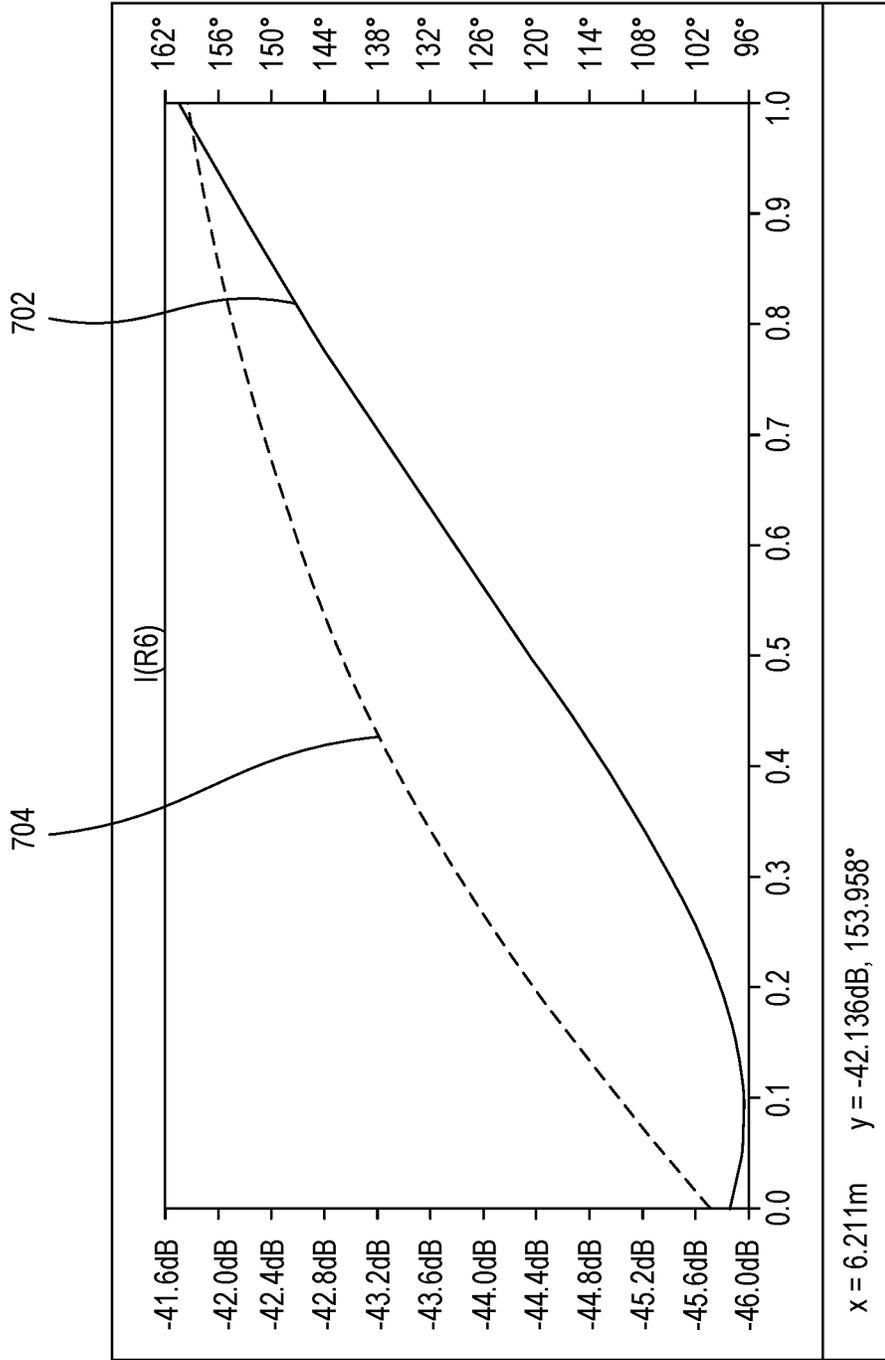


FIG. 7

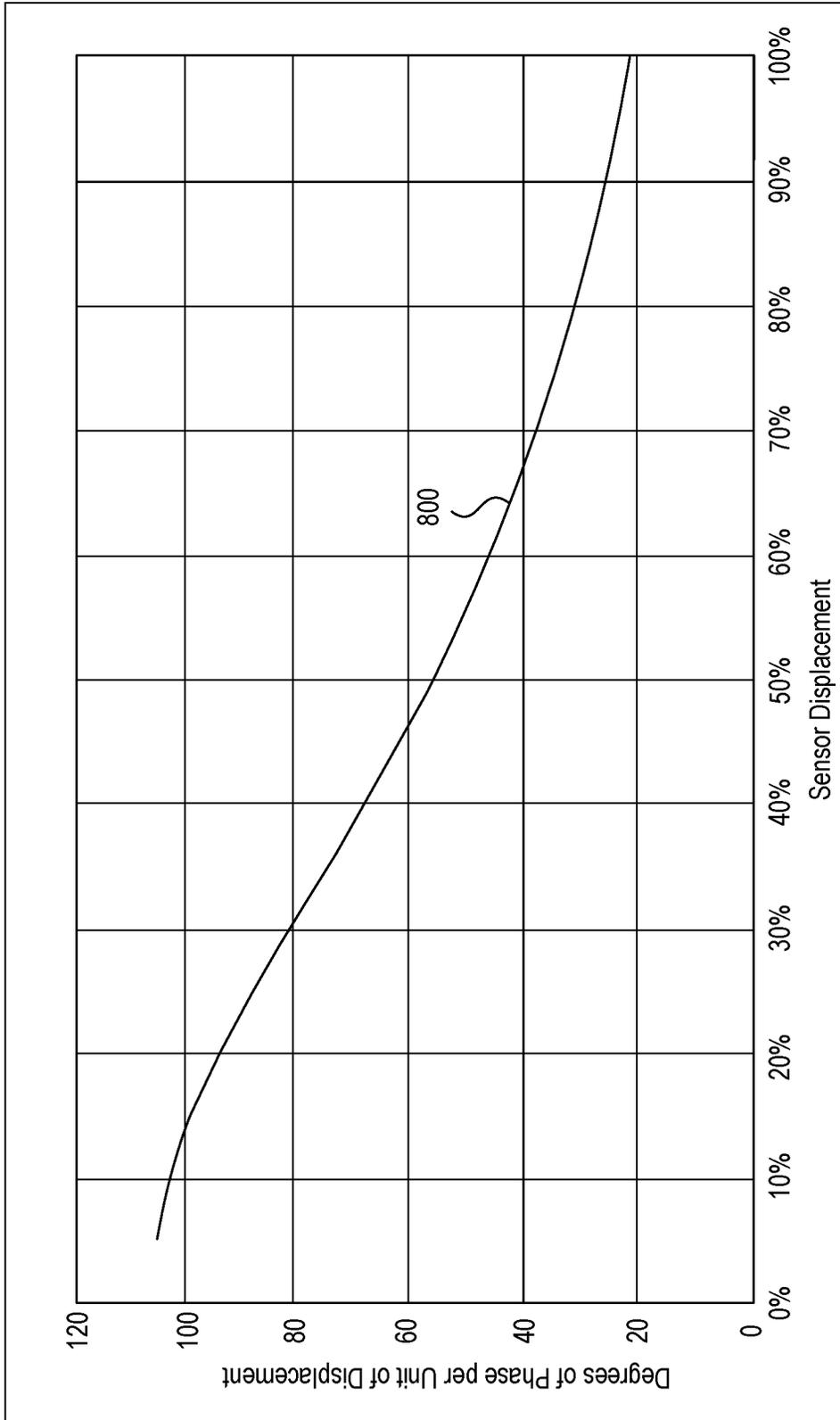


FIG. 8

900

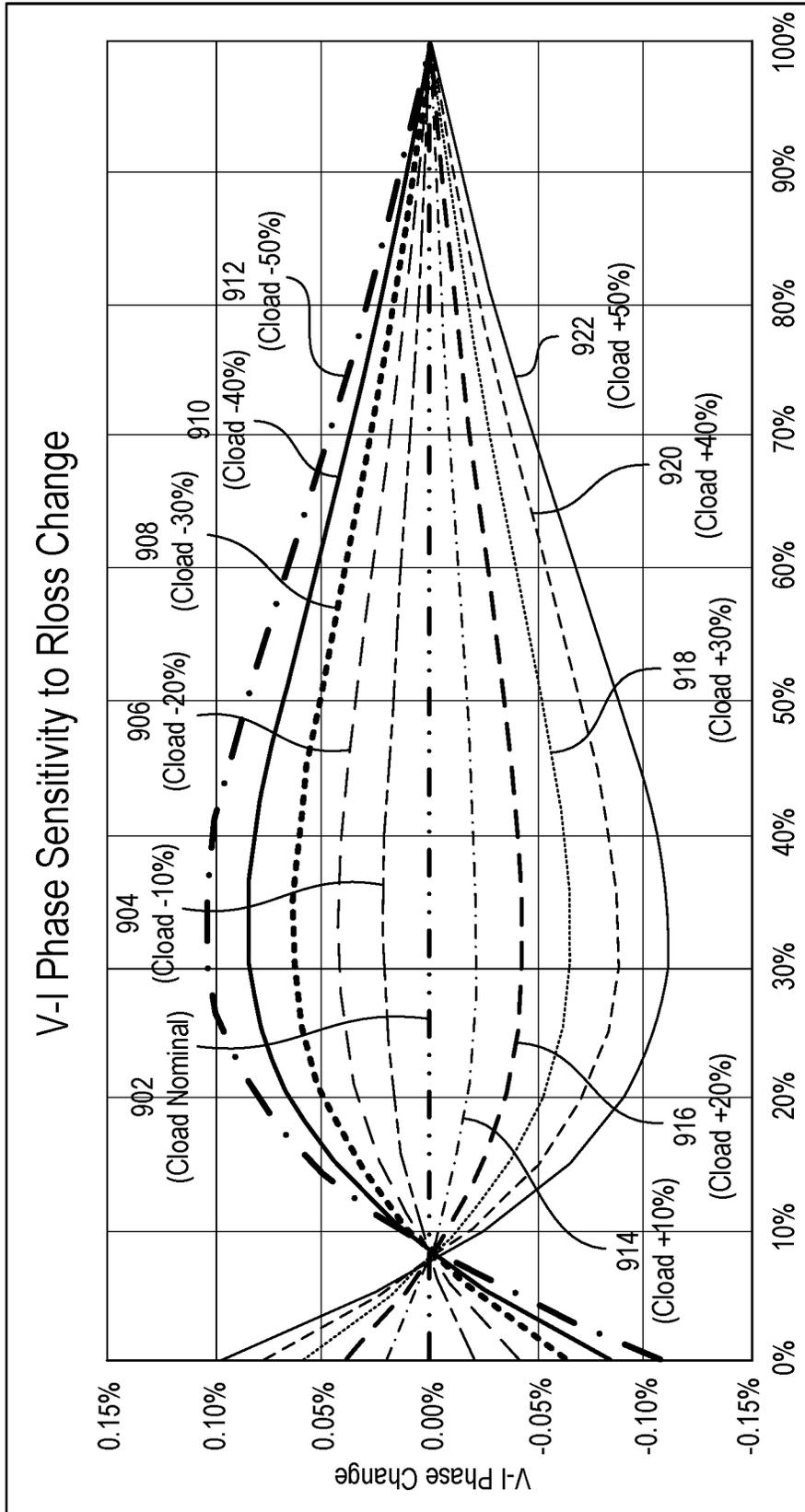


FIG. 9

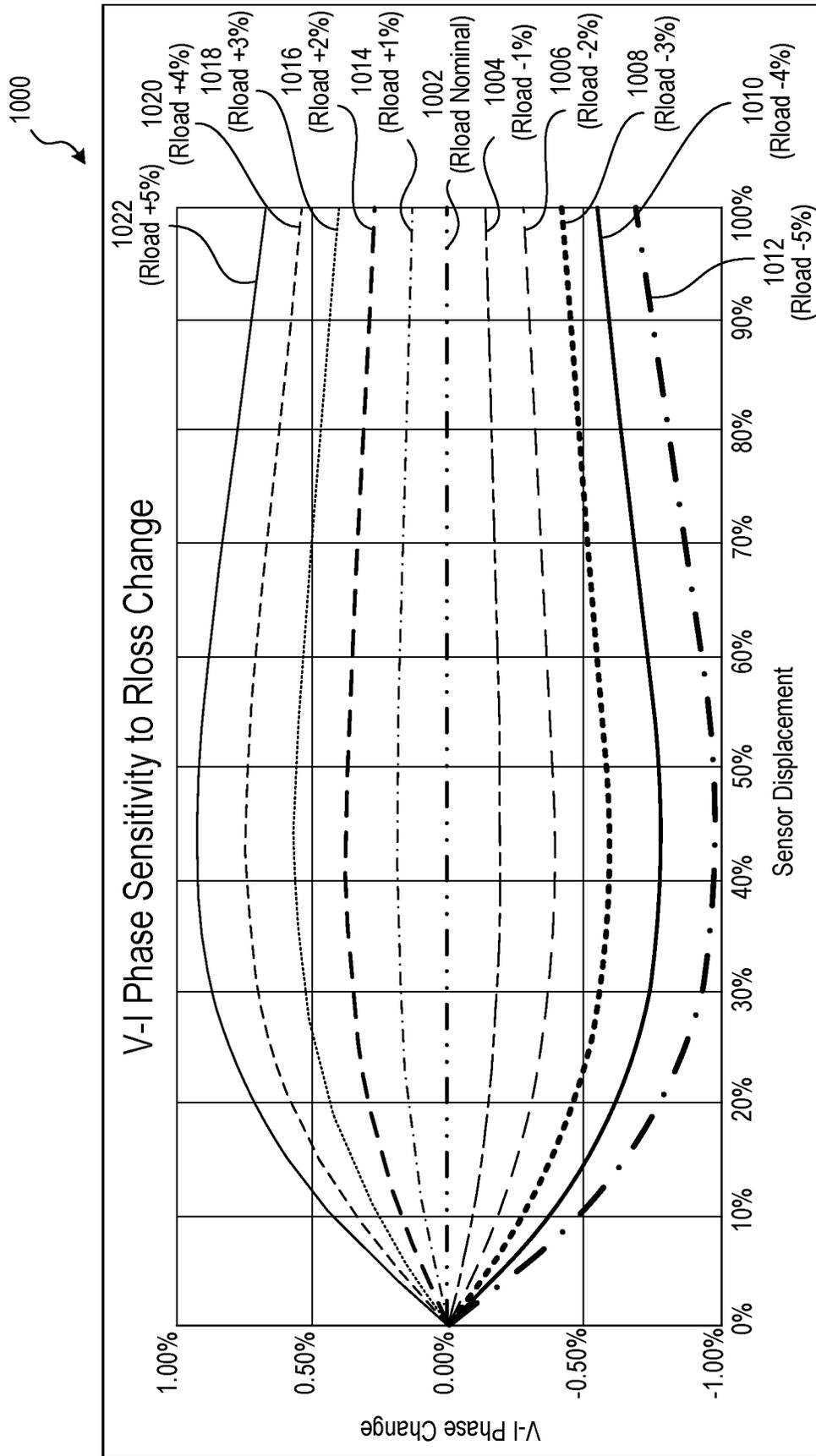


FIG. 10

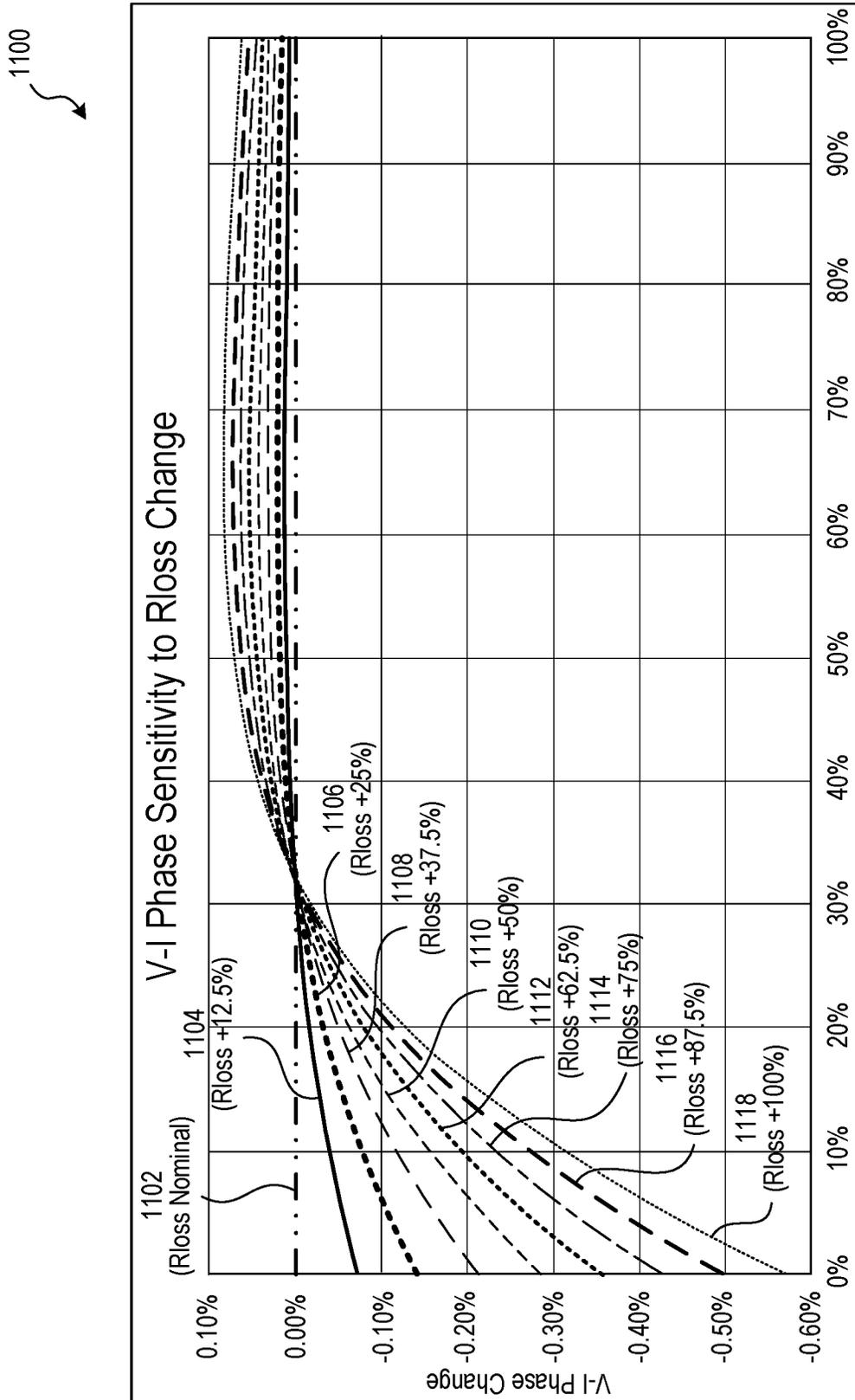


FIG. 11

1200

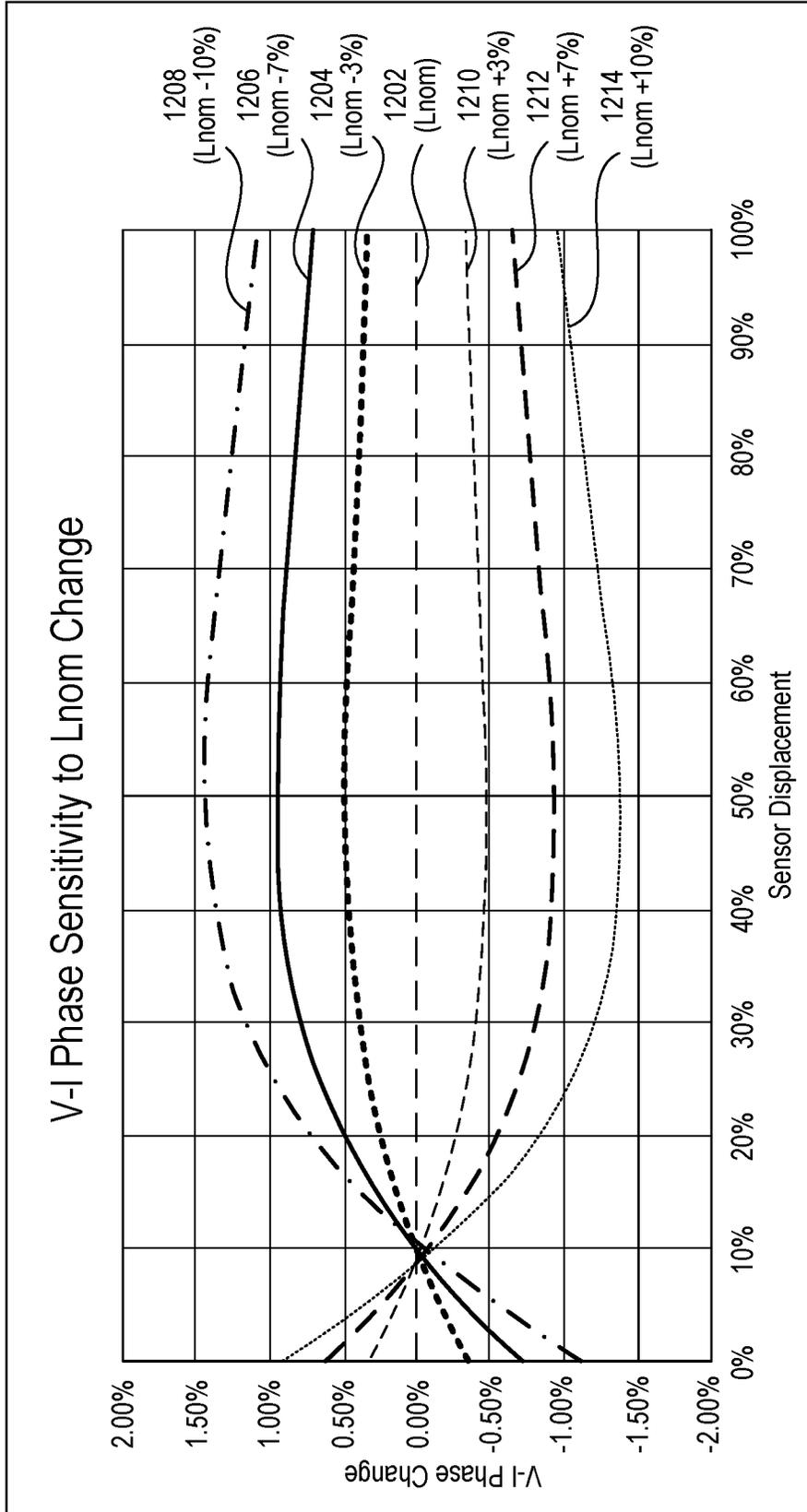


FIG. 12

1300

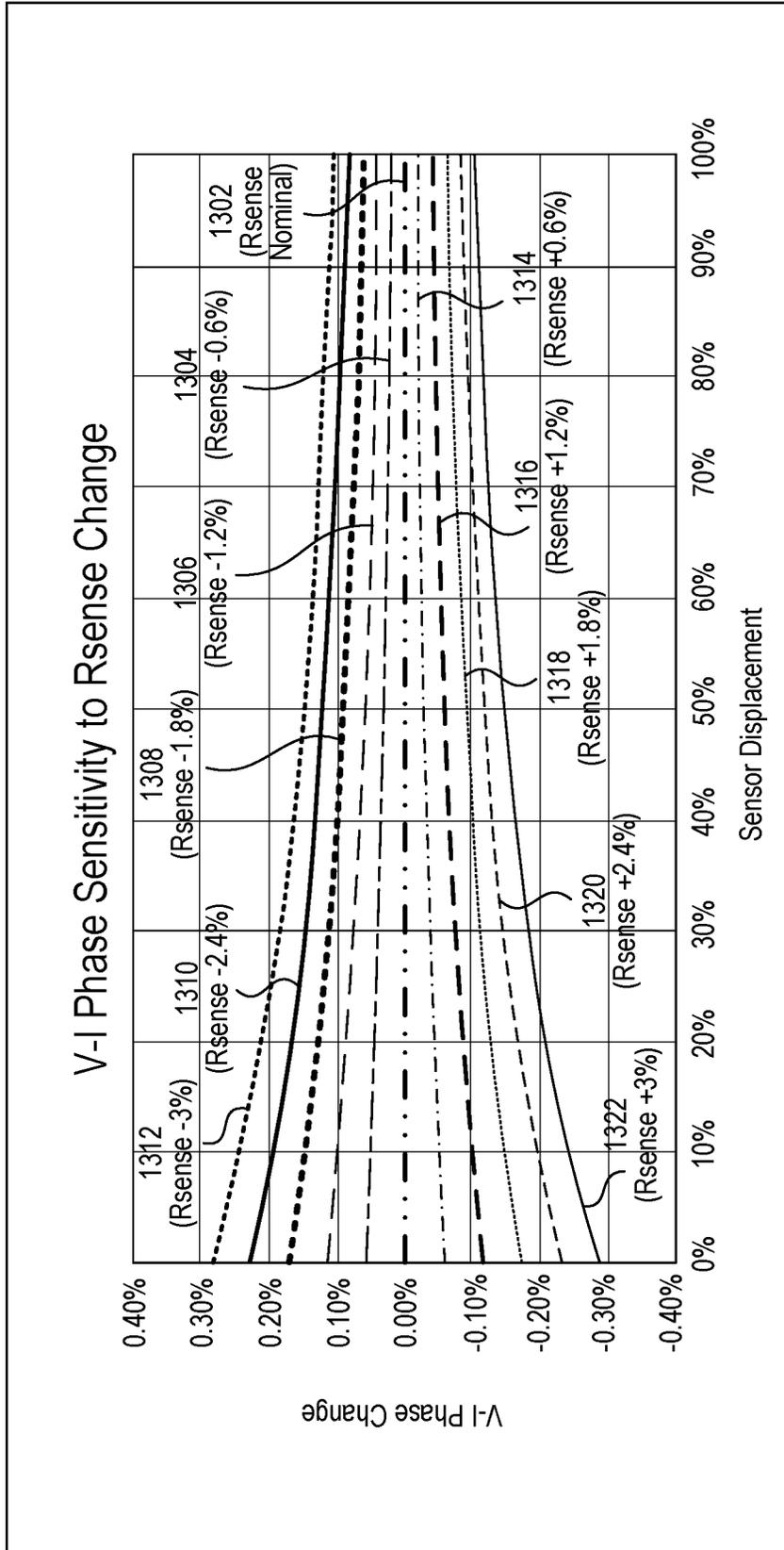


FIG. 13

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**VOLTAGE-CURRENT PHASE-BASED
METHOD FOR LINEAR AND ROTARY
TRANSFORMER SYSTEMS, AND
ASSOCIATED SYSTEMS AND METHODS**

CROSS-REFERENCE TO RELATED
APPLICATION(S)

The present application is a continuation of U.S. patent application Ser. No. 17/943,063, filed Sep. 12, 2022, now issued as U.S. Pat. No. 11,768,088, which is a continuation of U.S. patent application Ser. No. 16/899,458, filed on Jun. 11, 2020, now issued as U.S. Pat. No. 11,467,003, which are incorporated herein by reference in its entirety.

TECHNICAL FIELD

The present disclosure is directed generally to linear and/or rotary transformer systems that measure the position and/or angle of moving objects, and associated systems and methods.

BACKGROUND

Linear variable differential transformers (LVDTs) and rotary variable differential transformers (RVDTs) are used in a large variety of systems to measure a position or an angle, respectively, of another device. A ferrous core is attached to the moving device and as the device moves, the core moves relative to an excitation coil and two sensing coils. An excitation signal is generated on one or both of the sensing coils depending upon the position of the core. When the core is aligned between the excitation coil and the first sensing coil, the excitation signal shows up on the first sensing coil and not the second sensing coil. When the core is aligned between the excitation coil and the second sensing coil, the excitation signal shows up on the second sensing coil and not the first. For intermediate positions of the core, the excitation signal shows up proportionately on the first and second sensing coils, such that the ratio of the signals detected on the two sensing coils correspond to the position of the core. Therefore, the signals on the sensing coils are measured to determine the position of the core, and thus the position of the object.

A disadvantage of using the LVDT/RVDT is that all three coils need to be connected, which requires the use of six cables. Depending upon where the LVDT/RVDT is installed in the system, the system may require long and/or large wire bundles that can experience significant levels of noise. Another disadvantage is that relative errors in the measurements of the two sensing coils (e.g., due to differences in precision of the two measuring circuits and/or averaging circuits) can lead to result inaccuracies. Also, since root mean square (RMS) values are typically used for voltage measurements, additional delay is incurred in the measurement process due to the filtering process of the RMS values. Aspects of the present disclosure are directed to addressing at least these disadvantages.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 is a partially schematic illustration of a representative rocket system configured in accordance with embodiments of the present technology.

FIG. 2 is a schematic diagram of a linear transformer system used to detect linear movement of an object in accordance with embodiments of the present technology.

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FIG. 3 is a schematic diagram of a rotary transformer system used to detect rotational movement of an object in accordance with embodiments of the present technology.

FIG. 4 illustrates a linear transformer system interconnected with circuits configured to determine the position of the core of the transformer, which correlates to the position of an object connected to the core, in accordance with embodiments of the present technology.

FIG. 5 illustrates example digital waveforms corresponding to the first and second digital signals used to determine the position of the object connected to the core of the linear transformer system in accordance with embodiments of the present technology.

FIGS. 6A-6F illustrate different pseudo-loads that include first and second impedance loads that have different phase-shifting characteristics in accordance with embodiments of the present technology.

FIG. 7 illustrates a voltage-current relationship that is measured across the sensing resistor of FIG. 4 as the core moves along its range of motion between the first and second sensing coils in accordance with embodiments of the present technology.

FIG. 8 is a graph of phase change vs. displacement of the circuit of FIG. 4 in accordance with embodiments of the present technology.

FIG. 9 is a graph that shows the effect on phase-shift of changing the capacitance value of the capacitive element of a pseudo-load attached to the sensing coils of an LVDT/RVDT in accordance with embodiments of the present technology.

FIG. 10 is a graph that shows the effect on phase-shift of changing the resistance value of the resistive element of a pseudo-load attached to the sensing coils of an LVDT/RVDT in accordance with embodiments of the present technology.

FIG. 11 is a graph that shows the effect on phase-shift as transformer losses of an LVDT/RVDT increase in accordance with embodiments of the present technology.

FIG. 12 is a graph that shows the effect on phase-shift of changing the inductance value of an LVDT/RVDT in accordance with embodiments of the present technology.

FIG. 13 is a graph that shows the effect on phase-shift of changing the resistance value of the sensing resistor on the phase change in accordance with embodiments of the present technology.

DETAILED DESCRIPTION

Embodiments of the technology disclosed herein are directed generally to tracking the movement of objects such as fins and nozzles within a rocket system, and associated systems and methods. In particular, an LVDT and/or RVDT can include interconnected pseudo-loads that can cause phase-shifts in signals that are representative of the movement of the object. The phase-shift can be detected remotely from the LVDT/RVDT and the object being tracked. Fewer cables are needed to operate the LVDT/RVDT with the pseudo-loads, resulting to lower weight and space requirements in the rocket system.

FIG. 1 is a partially schematic illustration of a representative rocket system **100** configured in accordance with embodiments of the present technology. The system **100** can include a vehicle **101** (e.g., a launch vehicle) having a single or a multi-stage configuration. In the representative embodiment shown in FIG. 1, the vehicle **101** includes a first stage **102**, a second stage **103**, and a payload **104** (shown schematically in FIG. 1) surrounded by a fairing **105**. The first stage **102** and the second stage **103** operate as boosters to

direct the payload **104** into space. The first stage **102** can include one or more fins **114** that can be angularly adjusted to provide stability, control, and/or direction to the vehicle **101** during flight. In other embodiments, the vehicle **101** can include a single booster, or more than two boosters. In any of these embodiments, at least one of the boosters (e.g., the first stage **102**) is configured to be returned to Earth in a tail-down configuration, and is then reused on a subsequent launch.

The first stage **102** can include a propulsion system **110** that can in turn include one or more main engines **111** (positioned within the first stage **102**). Each main engine **111** can include a corresponding nozzle **112**. During launch, the main engines **111** provide the primary force directing the vehicle **101** upwardly. During a tail-down reentry, the thrust provided by the main engines **111** provides a braking force on the first stage **102** as it descends and lands in preparation for its next mission. In both cases, thrust is provided along a thrust axis TA, which can be adjusted to steer or maneuver the vehicle **101**. In some embodiments, an orientation of one or more of the nozzles **112** can be adjusted to steer, maneuver, and/or control the vehicle **101**.

Rocket systems **100** of the type shown in FIG. **1** include numerous actuators to control elements of the propulsion system and flight control system, among others. Sensors, including LVDTs and/or RVDTs, are often used to detect the motion of movable system components, e.g., to confirm that the actual motion matches the commanded motion. Standard LVDTs and/or RVDTs require six cables, which can result in large wire bundles that can run for a significant distance from the LVDT/RVDT to the control circuitry that commands and controls the movable object. This increases space requirements, cost, and potentially, time to troubleshoot a problem. Also, the standard LVDT/RVDT determines the position of an object by calculating an RMS value, resulting in a time delay. This can be a disadvantage in critical systems that rely on precise measurements and positioning within a very small time window.

As discussed further below, adjustments to the nozzles **112**, fins **114**, and/or other linearly and/or rotationally movable objects within the rocket system **100** can be controlled, facilitated and/or oriented by one or more linear transformer system and/or rotary transformer system. The linear and/or rotary transformers systems can be used in many other applications, including those that require long wire bundles, experience extreme heat and/or pressure conditions, and/or conditions that produce high levels of vibration. Other applications include those that may have limited space for cabling, as well as systems that can benefit from a faster determination of the position of the movable object.

FIG. **2** is a schematic diagram of a linear transformer system **200** used to detect linear movement of an object **212** in accordance with embodiments of the present technology. For objects that move rotationally, a rotary transformer system **300**, as discussed below and shown in FIG. **3**, can be used.

The linear transformer system **200** includes an LVDT **202** having an excitation coil **204** and first and second sensing coils **206**, **208**. In some embodiments, each of the excitation coil **204** and the first and second sensing coils **206**, **208** can have a 16 mH inductance and a series resistance of 2 ohms. A core **210** is configured to be operatively coupled (e.g., coupleable) to the object **212** through a linkage **248**. The linkage **248** is illustrated as a dotted line on FIG. **2**, and the implementation can vary based on the object **212**. For example, the object **212** can be one of the fins **114** and/or nozzles **112** (FIG. **1**).

Components within the linear transformer system **200** and connected thereto are subject to losses due to resistance. A resistive loss **214** represents the resistive loss value associated with a first cable **240** connected to the excitation coil **204**, and the internal resistance of the excitation coil **204** itself. Additional resistive losses **216**, **218** represent resistive loss values associated with the indicated cables and/or wires shown in FIG. **2** as well as the internal resistance of the first and second sensing coils **206**, **208**, respectively.

Pseudo-loads **220** are connected to the LVDT **202**. The term “pseudo-load” is used herein to refer to an impedance load with known resistance and/or capacitance values that is connected in a closed circuit with one or both of the first and second sensing coils **206**, **208**. Pseudo-loads **220** can include a first impedance load **222** connected to the first sensing coil **206** and a second impedance load **224** connected to the second sensing coil **208**. The first impedance load **222** has a first resistive element **226** and a first capacitive element **228** in series with the first sensing coil **206**. The second impedance load **224** has a second resistive element **230** in series with the second sensing coil **208**. One or both of the resistive elements **226**, **230** can be optional in some embodiments.

The pseudo-loads **220** can be co-located with (e.g., located nearby, adjacent to, within a common housing, and/or in very close proximity to) the LVDT **202**. In some embodiments, the linear transformer system **200** has a single housing that holds the pseudo-loads **220** and the LVDT **202** there within. In other embodiments, the first and second impedance loads **222** and **224** are physically separate from each other and the LVDT **202**. In yet further embodiments, the first and second impedance loads **222**, **224** of the pseudo-loads **220** are positioned within a first housing that is located near, and interconnected with, the LVDT **202**, which is located within a second housing. In other embodiments, the foregoing components can have other configurations and thus are not restricted by these examples.

In a representative embodiment, a sensing resistor **236** is connected to a sinusoidal waveform generation circuit **234** proximate a first terminal of the sensing resistor **236** and to the excitation coil **204** proximate a second terminal of the sensing resistor **236**. The sinusoidal waveform generation circuit **234** provides an input sinusoidal signal **238** that passes along a segment of the first cable **240** between the sinusoidal waveform generation circuit **234** and through the sensing resistor **236**. In some embodiments, a 2 KHz sinusoidal signal with a 500 μ s period at a constant amplitude can be used. Therefore, the input sinusoidal signal **238** has a constant amplitude and constant frequency. The signal delivered along a segment of the first cable **240** between the sensing resistor **236** and the excitation coil **204** is referred to herein as excitation coil input signal **244**. A second cable **242** returns from the excitation coil **204** to the sinusoidal waveform generation circuit **234** and is tied to common ground **232a**.

Each of the first and second impedance loads **222**, **224** has a different impedance angle in the real/imaginary plane. Each of the impedance angles has a corresponding angle difference in the voltage and current waveforms. Therefore, some impedance angles result in a phase-shift difference between the voltage and current waveforms as discussed below.

When the object **212** moves linearly, it moves the core **210** along a path indicated by arrow **246**. In general, when the position of the core **210** couples the excitation coil **204** with the second sensing coil **208**, which has a resistive load (e.g., the second impedance load **224** with the resistive element **230**), the excitation signal sees a mostly resistive

load. In this position, the current and voltage are approximately in phase when measured at the excitation coil 204. The phase-shift difference in this example corresponds to the impedance angle of the second impedance load 224. When the position of the core 210 couples the excitation coil 204 with the first sensing coil 206, which has a predominantly capacitive load (e.g., the first impedance load 222 with the capacitive element 228), the excitation signal sees a mostly capacitive load, which causes a phase difference of approximately 90 degrees between the voltage and current on the excitation coil 204. The phase-shift difference in this example corresponds to the impedance angle of the first impedance load 222.

When the position of the core 210 is in between the first and second impedance loads 222, 224, the phases of the voltage and current in the excitation coil 204 are correspondingly shifted (e.g. between zero and 90 degrees). In other words, the phase-shift difference corresponds to the impedance angle of the load seen by and/or coupled to the excitation of the excitation coil 204.

The voltage-current phase difference (e.g., the phase-shift or phase difference between the voltage and current), can also be detected on the excitation coil input signal 244 along the segment of the first cable 240 between the sensing resistor 236 and the excitation coil 204. However, the input sinusoidal signal 238 detected between the sensing resistor 236 and the sinusoidal waveform generation circuit 234 does not experience this voltage-current phase difference, allowing a measurable phase-shift between the two signals 238 and 244.

FIG. 3 is a schematic diagram of a rotary transformer system 300 used to detect rotational movement of an object 302 in accordance with embodiments of the present technology. In some embodiments, some of the components within the rotary transformer system 300 can be the same as components within the linear transformer system 200 of FIG. 2, and thus like item numbers are used.

A core 312 is configured to be operatively coupled to the object 302 through a linkage 314. The linkage 314 is illustrated as a dotted line in FIG. 3, and the implementation can vary based on the object 302 that is rotationally moving. In some embodiments, the object 302 is one of the fins 114 and/or nozzles 112 (FIG. 1).

The RVDT 304 is interconnected with the pseudo-loads 220, and each of the first and second impedance loads 222, 224 has a different impedance angle. Therefore, each of the first and second impedance loads 222, 224 has a different phase-shifting characteristic. The variations with respect to co-location and the housing of circuits and various components as discussed with respect to the linear transformer system 200 also apply to the rotary transformer system 300.

When the object 302 moves angularly (indicated by arrow 316), it moves the core 312 relative to the excitation coil 204 and the first and second sensing coils 206, 208. The position of the core 312 couples the excitation signal to one or both of the first and second sensing coils 206, 208, resulting in a voltage-current phase difference on the excitation coil input signal 244 along the segment of the first cable 240 between the sensing resistor 236 and the excitation coil 204.

FIG. 4 illustrates the linear transformer system 200 interconnected with circuits configured to determine the position of the core 210, which correlates to the position of the object 212, in accordance with embodiments of the present technology. The first and second impedance loads 222, 224 have different phase-shifting characteristics. As discussed above with reference to FIG. 2, the first impedance load 222 has a greater capacitive component than does the second imped-

ance load 224, and the second impedance load 224 has a greater resistive component than does the first impedance load 222.

A phase-shift sensing circuit 400 can be connected to the first cable 240 and can include a voltage comparator circuit 402 and a phase comparator circuit 404. The voltage comparator circuit 402 includes first and second comparators 406, 408. First and second input signals 410, 412 to the first comparator 406 correlate to the input sinusoidal signal 238 and the excitation coil input signal 244, respectively. The first input signal 410 (e.g., the input sinusoidal signal 238) is also input to the second comparator 408, while a second input 414 of the second comparator 408 is tied to common ground 232b. Voltage source 416 provides appropriate voltage levels to the first and second comparators 406, 408.

The first and second input signals 410, 412 are detected on either side of the sensing resistor 236. The first comparator 406 compares the signal voltage of the input sinusoidal signal 238 on the first input signal 410 to the signal voltage of the excitation coil input signal 244 on the second input signal 412 and outputs a first digital signal 418. In some embodiments, the first comparator 406 measures the voltage drop across the sensing resistor 236, which provides a measurement of the current waveform, as the voltage and current are in phase across the sensing resistor 236. In a representative embodiment, the first digital signal 418 is a square wave that represents a digital transformation of the excitation coil input signal 244. The second comparator 408 compares the signal voltage of the input sinusoidal signal 238 on the first input signal 410 to the common ground 232b on the second input 414 and outputs a second digital signal 420. In a representative embodiment, the second digital signal 420 is a square wave that represents a digital transformation of the input sinusoidal signal 238.

In general, the outputs of the first and second comparators 406, 408 can be compared to determine the position of the core 210. The first and second digital signals 418, 420 are then compared by the phase comparator circuit 404 to determine if there is a phase-shift (e.g., a timing difference) between the input sinusoidal signal 238 and the excitation coil input signal 244. In some embodiments, the phase comparator circuit 404 determines if there is a phase-shift by identifying and comparing rising and/or trailing edges of the first and second digital signals 418, 420. This can be achieved in many embodiments by using standard digital circuits (not shown), such as one or more microcontroller units (MCUs) and/or digital logic circuits. Determining the timing difference can be accomplished with no delay, because in several embodiments, an averaging circuit is not required. In other embodiments, an averaging circuit 422 can be used. In either case, the timing difference can be correlated with a position of the movable object 212.

In some embodiments, the sinusoidal waveform generation circuit 234, the sensing resistor 236 and the phase-shift sensing circuit 400 are not co-located with the linear transformer system 200, 300 (FIG. 3), but are located a distance away. In contrast to using a standard LVDT and/or RVDT that requires six cables to extend from the LVDT/RVDT to the measuring and control circuits, one of the advantages of using the transformer system 200, 300 is that only the first and second cables 240, 242 are needed. For example, the transformer system 200, 300 can be connected to one of the nozzles 112 (FIG. 1) in the propulsion system 110, or one of the fins 114 in the first stage 102 of the system 100 (e.g., near where a moving part is located and a measurement needs to be taken), while the sinusoidal waveform generation circuit 234, the sensing resistor 236 and the phase-shift sensing

circuit **400** are located a distance away (e.g., inside avionics systems, such as embedded controllers, engine controllers and/or other avionics) and connected via two cables and/or wires. Other control circuits (not shown) can be used to adjust and/or control the position of the moving object **212** based on the detected phase-shift.

In other embodiments, the sensing resistor **236** can be replaced with one or more elements that have capacitive, inductive and/or resistive characteristics, and/or a combination of some or all of these elements. However, if a component other than a resistive element is used, a phase-shift between the voltage and current can occur on the excitation coil input signal **244** when a purely resistive pseudo-load is connected to the LVDT **202**. This phase-shift can introduce additional calculations that need to be accomplished to determine the movement of the object **212**.

FIG. 5 illustrates example digital waveforms corresponding to the first and second digital signals **418** and **420** (FIG. 4) in accordance with embodiments of the present technology. These digital waveforms can be generated by either of the transformer systems **200**, **300** (FIGS. 2 and 3) when used together with the sinusoidal waveform generation circuit **234**, the sensing resistor **236** and phase-shift sensing circuit **400** (FIG. 4).

Voltage level is represented on the Y-axis and time is represented on the X-axis. Reference phase waveform **500** corresponds to the second digital signal **420** output from the second comparator **408** (FIG. 4). In other words, the reference phase waveform **500** is a square wave that represents a digital transformation of the input sinusoidal signal **238**. Rising edge **504** of the reference phase waveform **500** represents the time at which the voltage waveform of the input sinusoidal signal **238** crosses from negative to positive. Trailing edge **508** of the reference phase waveform **500** represents the time at which the voltage waveform of the input sinusoidal signal **238** crosses from positive to negative. The voltage and current are in phase prior to, and across, the sensing resistor **236**.

A plurality of sense phase waveforms **502** are also shown in FIG. 5. The sense phase waveforms **502** correspond to the first digital signal **418** output from the first comparator **406** as the core **210** moves over its range, coupling to the second impedance load **224** (which is all or mostly resistive) and then to the first impedance load **222** (which is mostly capacitive, see FIG. 4). The sense phase waveforms **502** can, in some embodiments, experience noise when transitioning between high and low, depending on the position of the core **210** with respect to the first and second sensing coils **206**, **208** (FIG. 4). If excessive noise is experienced, the averaging circuit **422** (FIG. 4) can be used to average the signals over a predetermined time interval.

The rising edge **506** of the first sense phase waveform **502** represents the point in time at which the voltage level of the input sinusoidal signal **238** (e.g., first input signal **410**) exceeds the voltage level of the excitation coil input signal **244** (e.g., second input signal **412**), and the output of the first comparator **406** goes high. The trailing edge **510** of the first sense phase waveform **502** represents the point in time at which the voltage level of the input sinusoidal signal **238** drops below the voltage level of the excitation coil input signal **244**, and the output of the first comparator **406** goes low.

As the core **210** (FIG. 4) moves between the two impedance loads **222**, **224**, the changing capacitance level of the coupled load has a direct effect on the phase of the current that is on the excitation coil **204**. When the core **210** is coupled with an impedance load that is mostly resistive (e.g.,

the second impedance load **224**), the rising edge **506** of the sense phase waveform **502** is delayed by a timing difference **512** compared to the rising edge **504** of the reference phase waveform **500** that represents a voltage drop across sensing resistor **236**. In some embodiments the timing difference **512** can be present even when the impedance load is purely resistive. As the core **210** moves and couples to an increasingly capacitive impedance load, the timing difference **512** between the rising edge **506** of the sense phase waveform **502** and the rising edge **504** of the reference phase waveform **500** increases.

FIGS. 6A-6F are schematic illustrations of pseudo-loads suitable for use with the transformer systems **200**, **300** (FIGS. 2, 3) in accordance with further embodiments of the present technology. Although various configurations are shown, the first and second impedance loads within the pseudo-loads can include more or fewer resistive elements (e.g., resistors), capacitive elements (e.g., capacitors), and/or inductive elements (e.g., inductive coils), as long as the phase-shifting characteristics of the first and second impedance loads are different from each other and result in a measurable phase-shift that can be indicated by the timing difference **512** (FIG. 5).

FIG. 6A shows a pseudo-load **600** that includes first and second impedance loads **602**, **604** configured in accordance with embodiments of the present technology. The first impedance load **602** includes a capacitive element **606**. The second impedance load **604** does not include an additional resistive or capacitive element. Therefore, the first impedance load **602** is more capacitive than the second impedance load **604**, and the first and second impedance loads **602**, **604** have different phase-shifting characteristics (e.g., different impedance angles).

In some embodiments, and as shown in FIG. 6A, the pseudo-load **600** is connected to the first and second sensing coils **206**, **208** (FIG. 4) of the LVDT **202**. As discussed previously, the resistive loss **216**, **218** represents the resistance in the associated first and second sensing coils **206**, **208** and can also include the resistance of the wiring and/or other connections between the first and second sensing coils **206**, **208** and the connected impedance load **602**, **604**.

FIG. 6B shows a pseudo-load **612** that includes first and second impedance loads **614**, **616** configured in accordance with further embodiments of the present technology. The first impedance load **614** includes a capacitive element **618** and a resistive element **620**. The second impedance load **616** does not include an additional resistive or capacitive element. Therefore, the first impedance load **614** is more capacitive than the second impedance load **616**, and the first and second impedance loads **614**, **616** have different phase-shifting characteristics.

FIG. 6C shows a pseudo-load **626** that includes first and second impedance loads **628**, **630** configured in accordance with still further embodiments of the present technology. The first impedance load **628** includes a capacitive element **632**, and the second impedance load **630** includes a resistive element **636**. As with embodiments shown in FIGS. 6A and 6B, the first impedance load **628** is more capacitive than the second impedance load **630**, and thus the first and second impedance loads **628**, **630** have different phase-shifting characteristics.

FIG. 6D shows a pseudo-load **640** that includes first and second impedance loads **642**, **644** configured in accordance with yet further embodiments of the present technology. The first impedance load **642** includes a capacitive element **646** and a resistive element **648**. The second impedance load **644** includes a capacitive element **652**. The capacitive values of

the first and second impedance loads **642**, **644** are different to result in different phase-shifting characteristics. For example, in some embodiments, the capacitive element **646** can have a value of $10\ \mu\text{F}$ and the capacitive element **652** can have a value of $100\ \mu\text{F}$, while the resistive element **648** can have a value of $33\ \Omega$.

FIG. 6E shows a pseudo-load **656** having a first impedance load **658** that includes a first capacitive element **662** and a first resistive element **664**, and a second impedance load **660** that includes a second capacitive element **668** and a second resistive element **670** configured in accordance with embodiments of the present technology. As with the embodiment shown in FIG. 6D, the capacitive values are different and thus have different phase-shifting characteristics. For example, in some embodiments, the capacitive element **662** can have a value of $10\ \mu\text{F}$ and the capacitive element **668** can have a value of $100\ \mu\text{F}$, while the resistive elements **664**, **670** can both be $33\ \Omega$.

FIG. 6F shows a pseudo-load **674** that includes first and second impedance loads **676**, **678** configured in accordance with embodiments of the present technology. The first impedance load **676** includes an inductive element **680**, while the second impedance load **678** has the resistive loss **218** of the wiring. The first and second impedance loads **676**, **678** have different phase-shifting characteristics (i.e. different impedance angles). In still further embodiments, one or more resistive elements and/or capacitive elements can be included in the first and second impedance loads **676**, **678**.

FIG. 7 illustrates a voltage-current relationship **702** measured across the sensing resistor **236** (FIG. 4) as the core **210** moves along its range of motion relative to the first and second sensing coils **206**, **208**, in accordance with embodiments of the present technology. The phase angle **704** is also shown. In some embodiments, the relationship between the displacement of the core **210** (e.g., shown along the X-axis) and the voltage-current relationship **702** is monotonic, and varies between about 100 degrees to about 160 degrees. This allows approximately 60 degrees of phase difference to measure the displacement of the core **210** from 0 to 100%. The phase change, however, may not be linear with displacement.

FIG. 8 shows that the sensitivity of the circuit (FIG. 4), measured as phase change vs. displacement (line **800**), is more sensitive on one end of the displacement range than the other, in accordance with embodiments of the present technology. In some embodiments, using a 2 KHz sinusoidal excitation ($500\ \mu\text{s}$ period), the phase differences as measured on either side of the sensing resistor **236** (FIG. 4) yields a sensitivity per 1% displacement between $1.45\ \mu\text{s}$ (e.g., best case and/or most sensitive) to $0.31\ \mu\text{s}$ (e.g., worst case and/or least sensitive). Therefore, to measure a position with 1% resolution, a time resolution of $0.31\ \mu\text{s}$ or better may be needed. This can easily be achieved in many embodiments using standard digital circuits (e.g., an MCU and/or digital logic circuit).

One advantage of embodiments of the present technology is that time-based and phase-based measurements (instead of voltage measurements that are sampled at the first and second sensing coils **206**, **208**) can produce greater immunity to component parameter variations. FIGS. 9-13 show simulations of the sensitivity of the phase-shift measurement technique to variations of several key component values. The discussion below applies to systems described above, including those shown in FIGS. 2-4.

FIG. 9 is a graph **900** that shows the effect on phase-shift of changing the capacitance value of the capacitive element of the load (e.g., the capacitive element **228** of the pseudo-

load **220** (FIGS. 2-4)) in accordance with embodiments of the present technology. The phase change response is shown versus the displacement of the core **210**.

When the capacitive element **228** has its nominal capacitance value (Cload Nominal), the phase change response as the core **210** is displaced is shown by a first line **902**. As the capacitance value of the capacitive element **228** is decreased relative to the nominal capacitance value (indicated as Cload -10%, Cload -20%, Cload -30%, Cload -40%, and Cload -50%), the phase change response as the core **210** is displaced is shown with second-sixth lines **904**, **906**, **908**, **910**, and **912**, respectively. As the capacitance value of the capacitive element **228** is increased relative to the Cload Nominal (indicated as Cload +10%, Cload +20%, Cload +30%, Cload +40%, and Cload +50%), the phase change response as the core **210** is displaced is shown with seventh-eleventh lines **914**, **916**, **918**, **920**, and **922**, respectively.

As shown by Cload -50% (line **912**) and Cload +50% (line **922**), a change of 50% in the capacitance value has a maximum effect of about 0.1% on the phase measurement. The insensitivity of the response to relatively large changes in capacitance is relevant, as the pseudo-load **220**, **320** co-located with the LVDT **202** and/or RVDT **304** can be the component experiencing the highest value change, given possible extreme environmental conditions the pseudo-load **220**, **230** can be exposed to, such as heat changes when located near engines **111** in the rocket system **100** of FIG. 1. In addition, capacitive elements (e.g., capacitors) generally have larger temperature change coefficients than resistors, and the demonstrated level of insensitivity contributes to a more reliable and predictable circuit response.

FIG. 10 is a graph **1000** that shows the effect on phase-shift of changing the resistance value of the resistive element of the load (e.g., the resistive element **226** of the pseudo-load **220** (FIGS. 2-4)) in accordance with embodiments of the present technology. Again, the phase change response is shown versus displacement of the core **210**.

When the resistive element **226** has its nominal resistance value (Rload Nominal), the phase change response as the core **210** is displaced is shown with a first line **1002**. As the resistance value of the resistive element **226** is decreased relative to the nominal value (indicated as Rload -1%, Rload -2%, Rload -3%, Rload -4%, and Rload -5%), the phase change response as the core **210** is displaced is shown with second-sixth lines **1004**, **1006**, **1008**, **1010**, and **1012**, respectively. As the resistance value of the resistive element **226** is increased relative to the Rload Nominal (line **1002**) (indicated as Rload +1%, Rload +2%, Rload +3%, Rload +4%, and Rload +5%), the phase change response as the core **210** is displaced is shown with seventh-eleventh lines **1014**, **1016**, **1018**, **1020**, and **1012**, respectively. As shown by Rload -5% (line **1012**) and Rload +5% (line **1022**), changing the resistance value of the resistive element **226** has a maximum effect of less than 1% on the phase measurement.

FIG. 11 is a graph **1100** that shows the effect on phase-shift as transformer losses increase, modeled as a series resistance in the excitation coil **204** (FIGS. 2-4) and the first and second sensing coils **206**, **208** in accordance with embodiments of the present technology. When the coils **204**, **206**, **208** of the LVDT **202** have their nominal resistance loss value (Rloss Nominal), the phase change response as the core **210** is displaced is shown with a first line **1102**. As the resistive loss increases relative to the nominal resistance loss value (indicated as Rloss +12.5%, Rloss +25%, Rloss +37.5%, Rloss +50%, Rloss +62.5%, Rloss +75%, Rloss +87.5%, and Rloss +100%), the phase change response as

the core **210** is displaced is shown with second-ninth lines **1104**, **1106**, **1108**, **1110**, **1112**, **1114**, **1116**, and **1118**, respectively. As shown by $R_{loss} +100\%$ (line **1118**), an increase of 100% of the transformer loss has a maximum effect of less than 0.6% on the phase measurement.

FIG. **12** is a graph **1200** that shows the effect on phase-shift of changing the inductance value of the excitation coil **204** (FIGS. **2-4**) and the first and second sensing coils **206**, **208** in accordance with embodiments of the present technology. When the coils **204**, **206**, **208** of the LVDT **202** have their nominal inductance value (L_{nom}), the phase change response as the core **210** is displaced is shown with a first line **1202**. As the inductance is reduced relative to the nominal inductance value (indicated as $L_{nom} -3\%$, $L_{nom} -7\%$, and $L_{nom} -10\%$), the phase change response as the core **210** is displaced is shown with second-fourth lines **1204**, **1206**, and **1208**, respectively. As the inductance is increased relative to the nominal inductance value (indicated as $L_{nom} +3\%$, $L_{nom} +7\%$, and $L_{nom} +10\%$), the phase change response as the core **210** is displaced is shown with fifth-seventh lines **1210**, **1212**, and **1214**, respectively. As shown by $L_{nom} -10\%$ (line **1208**) and $L_{nom} +10\%$ (line **1214**), a change of 10% on sensor inductance has a maximum effect of less than 1.5% on the phase measurement.

FIG. **13** is a graph **1300** that shows the effect on phase-shift of changing the resistance value of the sensing resistor **236** (FIGS. **2-4**) on the phase change in accordance with embodiments of the present technology. When the sensing resistor **236** has its nominal resistance value (R_{sense} Nominal), the phase change response as the core **210** is displaced is shown with a first line **1302**. As the resistance is reduced relative to the nominal resistance value (indicated as $R_{sense} -0.6\%$, $R_{sense} -1.2\%$, $R_{sense} -1.8\%$, $R_{sense} -2.4\%$, and $R_{sense} -3\%$), the phase change response as the core **210** is displaced is shown with second-sixth lines **1304**, **1306**, **1308**, **1310**, and **1312**, respectively. As the resistance is increased relative to the nominal resistance value (indicated as $R_{sense} +0.6\%$, $R_{sense} +1.2\%$, $R_{sense} +1.8\%$, $R_{sense} +2.4\%$, and $R_{sense} +3\%$), the phase change response as the core **210** is displaced is shown with seventh-eleventh lines **1314**, **1316**, **1318**, **1320**, and **1322**, respectively.

As shown by $R_{sense} -3\%$ (line **1312**) and $R_{sense} +3\%$ (line **1322**), a change of 3% on the sensing resistance value has a maximum effect of less than 0.3% on the phase measurement. The total value of sensing resistance can include the wiring resistance from the sensing resistor **236** to the LVDT **202**, which varies with parameters such as length and material used. However, these effects can be nullified via calibration. In some embodiments the resistance of the sensing resistor **236** may not change by a large amount if it is not co-located with the transformer system **200**, **300** (FIG. **2-4**) and is not exposed to wide environmental conditions.

As discussed herein, advantages of the transformer system **200**, **300** (FIGS. **2-4**) can include reducing the number of cables needed to connect the device to its sensing circuit **400** (FIG. **4**). This can simplify installation, reduce troubleshooting, and reduce the space and weight requirements associated with the device, which is important in rocket system applications. The transformer system **200**, **300** can be located remote from the sensing circuit **400** and can be housed in locations that experience extreme heat and/or vibration loads and/or load changes without experiencing a degradation in performance. Also, the sensing circuit **400** can determine the position of a linear or rotary movable device that is attached to the transformer system **200**, **300**

with a single measurement, rather than an average over time, providing very fast feedback from critical components such as fins and nozzles.

From the foregoing, it will be appreciated that specific embodiments of the disclosed technology have been described herein for purposes of illustration, but that various modifications may be made without deviating from the technology. For example, the linear transformer system and the rotary transformer system can be used in a variety of applications to control any object currently controlled with a standard LVDT/RVDT. The linear and/or rotary transformer system can accomplish this control of an object more quickly than a standard LVDT/RVDT, as it does not require voltage averaging circuits. In some embodiments, the transformer system **200**, **300** can be used with the rocket system **100** of FIG. **1** to measure a position of a fuel/oxidizer valve piston, determine an orientation of an engine nozzle **112**, and/or determine a position of a hydraulic piston that rotates one of the fins **114**. Certain aspects of the technology described in the context of particular embodiments may be combined or eliminated in other embodiments. Further, while advantages associated with certain embodiments of the disclosed technology have been described in the context of those embodiments, other embodiments may also exhibit such advantages, and not all embodiments need necessarily exhibit such advantages to fall within the scope of the present technology. Accordingly, the disclosure and associated technology can encompass other embodiments not expressly shown or described herein.

As used herein, the terms “generally” and “approximately” refer to values or characteristics within a range of $\pm 10\%$ from the stated value or characteristic, unless otherwise indicated. Furthermore, the phrase and/or, as in “A and/or B”, refers to A alone, B alone, and both A and B.

I claim:

1. A system configured to detect movement of an object, comprising:

a transformer circuit including:

an excitation signaling component configured to receive an excitation signal that corresponds to a periodic signal;

first and second signaling components;

a core configured to move relative to the first and second signaling components according to the movement of the object, wherein the core is configured to wirelessly couple the excitation signaling component to the first signaling component, the second signaling component, or a combination thereof based on a position of the core relative to the first and second signaling components;

first and second loads connected to the first and second signaling components, respectively, wherein the first load is different from the second load; and

a sensing circuit configured to determine a difference between the excitation signal and the periodic signal, the difference corresponding to the position of the core.

2. The system of claim 1, further comprising a sensing resistor configured to (1) receive the periodic signal and (2) provide the excitation coil input signal to the excitation signaling component, the sensing circuit further configured to determine the difference across the sensing resistor.

3. The system of claim 2, wherein the sensing circuit further includes:

a first comparator configured to generate a first digital signal based on comparing the excitation coil input signal and the input sinusoidal signal; and

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a second comparator configured to generate a second digital signal based on the periodic signal, wherein the sensing circuit is configured to determine the position of the core based on an offset between the first and second digital signals.

4. The system of claim 1, wherein the first and second impedance loads have different capacitances that correspond to the different phase-shifting characteristic.

5. The system of claim 1, wherein the first and second impedance loads have different resistances in addition to the different phase-shifting characteristic.

6. The system of claim 1, wherein the sensing circuit is located farther away from the object than the first and second impedance loads.

7. The system of claim 1, further comprising first and second wires connecting the sensing circuit with the transformer system, the sensing circuit being located remote from the transformer system.

8. The system of claim 1, wherein the transformer system is a linear transformer system.

9. The system of claim 1, wherein the transformer system is a rotary transformer system.

10. The system of claim 1, wherein the object is a movable component on a flight vehicle.

11. A transformer circuit configured to identify a position of an object or a change in the position, the transformer circuit comprising:
 an excitation signaling component configured to receive an excitation signal;
 a first signaling component including a first load;
 a second signaling component located away from the first signaling component and including a second load different from the first load; and
 a core (1) located between the excitation signaling component and the first and second signaling components and (2) configured to move relative to the first and second signaling components according to the position of the object thereby inductively coupling the excitation interface to the first signaling component, the second signaling component, or a combination thereof.

12. The transformer circuit of claim 11, wherein the first and second loads have different capacitances that correspond to different phase-shifting characteristic.

13. The transformer circuit of claim 12, wherein the first and second loads have different resistances in addition to the different phase-shifting characteristic.

14. The transformer circuit of claim 12, wherein the core is configured to move linearly relative to the first and second signaling components.

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15. The transformer circuit of claim 12, wherein the core is configured to move rotationally relative to the first and second signaling components.

16. A method of identifying a position of an object or a change in the position, the method comprising:
 providing a periodic signal;
 inductively communicating the periodic signal to at least one of a first load and a second load using a core configured to move according to a movement of the object, wherein the core is configured to move along a path associated with locations of the first and second loads;
 detecting a loaded signal that represents the periodic signal having been changed according to the inductive coupling between the excitation signaling component and the at least one of the first and second loads according to a location of the core along the path; and
 determining the position of the core based on a difference between the periodic signal and the loaded signal.

17. The method of claim 16, further comprising:
 generating a first digital signal based on comparing the periodic signal and the loaded signal; and
 generating a second digital signal based on the periodic signal, and
 wherein the determined position of the core is based at least in part on a delay between the first and second digital signals.

18. The method of claim 17, wherein determining the position includes comparing corresponding edges of the first and second digital signals to determine the delay.

19. The method of claim 16, wherein:
 the first and second loads correspond to ends of the path for the core;
 the first and second loads include different phase-shifting components; and
 the position of the core is determined based on a phase shift or a magnitude of a phase shifted component in the loaded signal in comparison to the periodic signal.

20. The method of claim 19, wherein:
 the first and second loads include different capacitances; and
 the position of the core is determined based on the phase shift or the magnitude of the phase shifted component that represents distances from the first and second loads along the path and corresponding influences from the different capacitances.

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